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TITLE: SELF-DRIVING METHOD OF TRUCK

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ABSTRACT:

PURPOSE: To set easily a driving target and to improve greatly the working efficiency by keeping the differences of angles formed by the straight lines connecting markers and left and right image sensors and center line of a truck within a set range respectively.

CONSTITUTION: Markers 6 and 7 are set on a virtual driving target (1c) with a prescribed distance (y) secured between them. The images of markers 6 and 7 are projected to a pair of image sensors 4 respectively. These sensors 4 detect the right-left displacement distance to optical axes (1b) of those images. Based on the result of this detection, each camera 5 calculates successively at the angles θ1a, θ1b, θ2a and θ2b formed by markers 6 and 7 respectivly through an automatic controller. Then an automatic controller controls an automatic steering device to a driving device 1 so as to maintain relations θ1a-θ1b≦ε1 and θ2a-θ2b≦ε2 in terms of the absolute values of said angles. Thus the direction and the right-left position can be corrected for a truck body A.